AMENDMENTS TO THE ABSTRACT

Replace the Abstract with the following:

A vehicle surroundings monitoring apparatus inputs images taken by a stereoscopic camera, vehicle speeds, steering wheel rotation angles, yaw rates and ON-OFF signals of a turn signal switch. An own traveling path C is calculated from an own traveling path A obtained from lane markers and side walls and an own traveling path B obtained from yaw rates of the own vehicle. Further, a new own traveling path E is calculated from the own traveling path C and a trace of a preceding vehicle, in case where there is no possibility of ~~evacuation~~a lane change of the preceding vehicle and the turn signal switch is turned off and the absolute value of the steering wheel rotation angle is smaller than a specified value and a present own traveling path is calculated from the own traveling path E and the previous own traveling path. In other cases, the present own traveling path is calculated from the own traveling path C and the previous own traveling path.